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(54) **DYNAMIC ORTHOSCOPIC SENSING**

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(58) **Field of Classification Search**

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See application file for complete search history.

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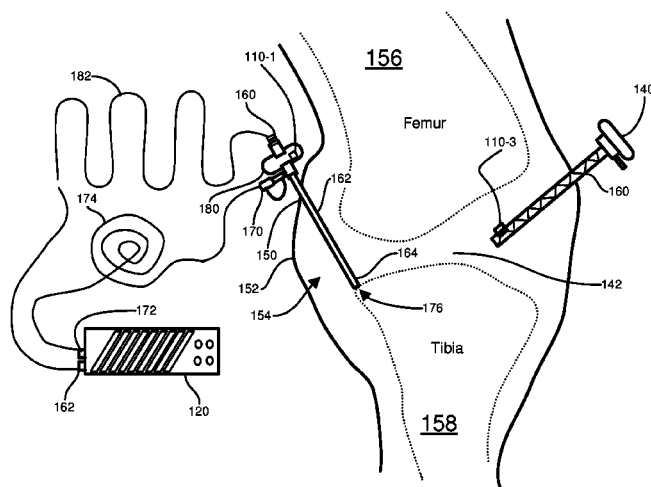
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(57) **ABSTRACT**

A dynamic sensing method and apparatus employs micro-electromechanical systems (MEMS) and nanoelectromechanical (NEMS) surgical sensors for gathering and reporting surgical parameters pertaining to a drive mechanism of a surgical device, such as speed, rotation, torque and other characteristics of the surgical device. The surgical device employs or affixes the surgical sensor on or about a surgical device for detecting electromechanical characteristics during the surgical procedure. The surgical procedure disposes the medical device in the surgical field responsive to the drive mechanism of a shaver or other endoscopic instrument inserted in a surgical field defined by the surgical procedure.

20 Claims, 6 Drawing Sheets



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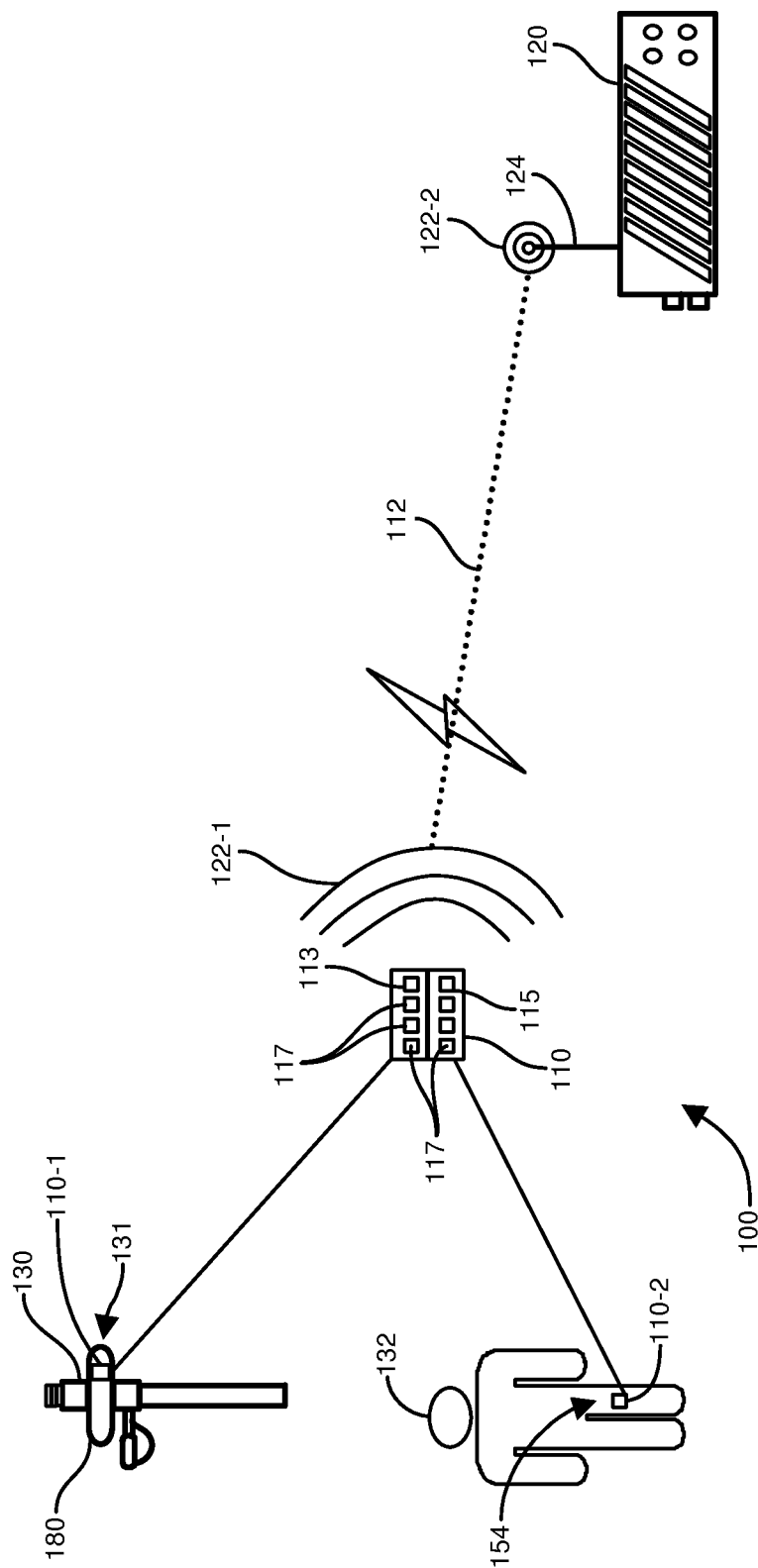
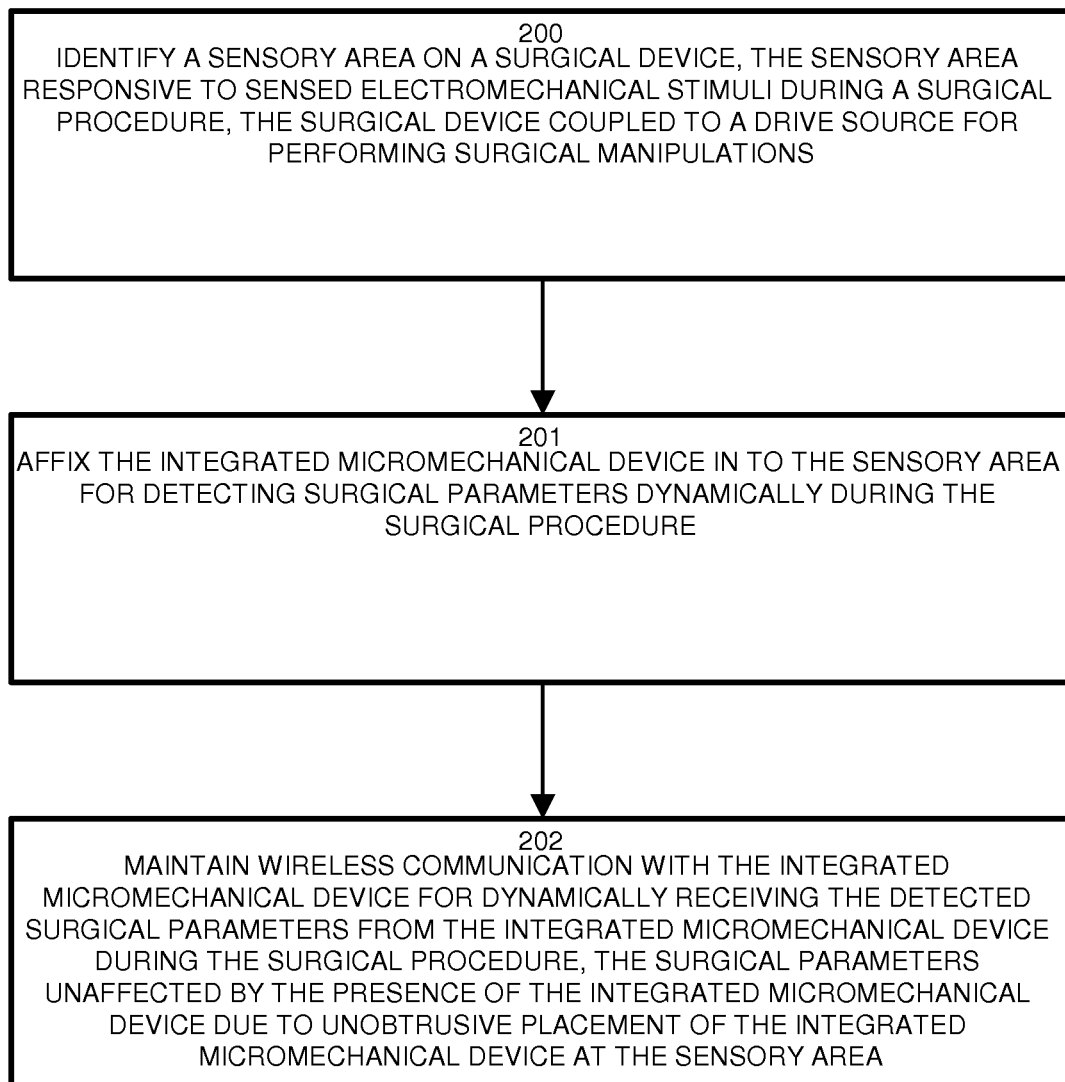


Fig. 1

**Fig. 2**

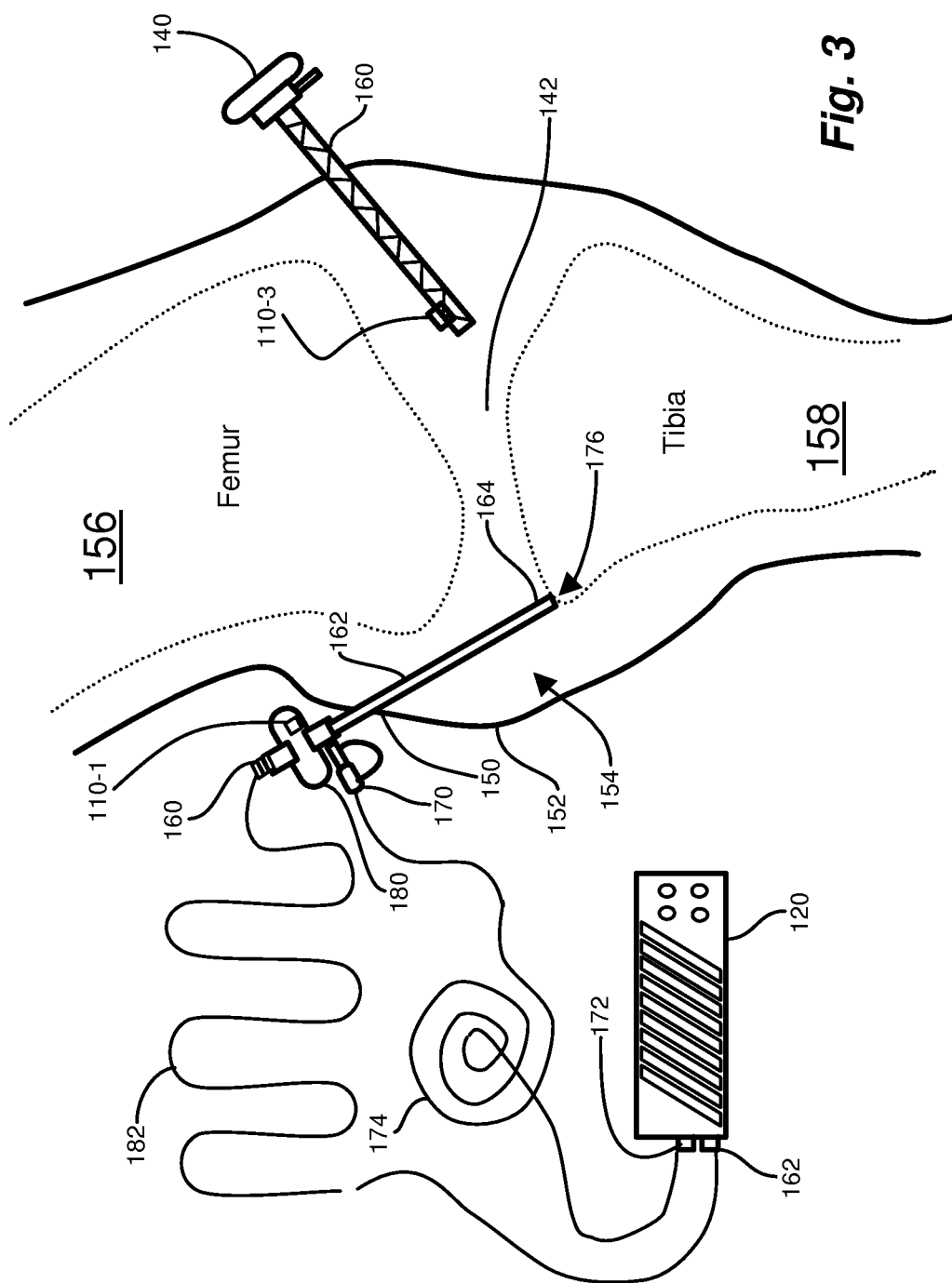
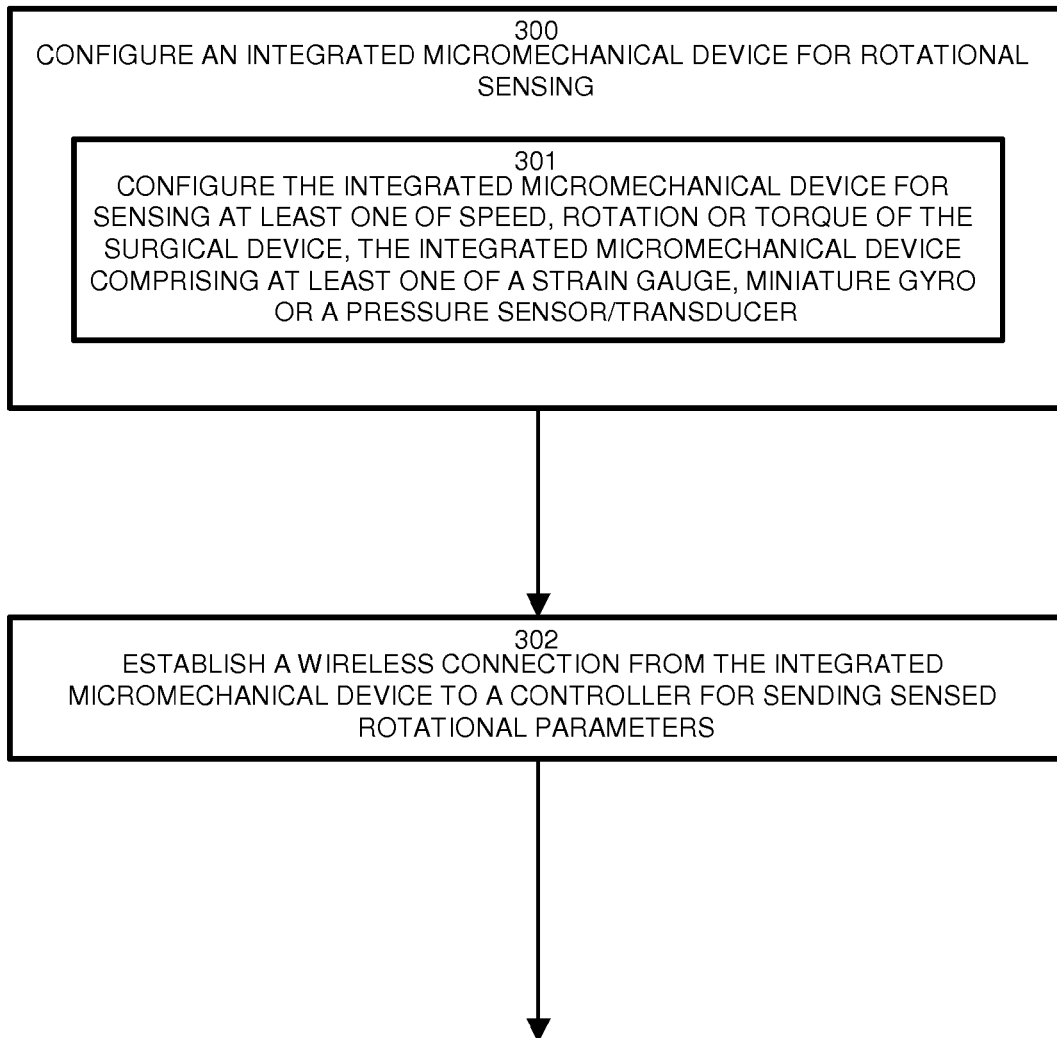
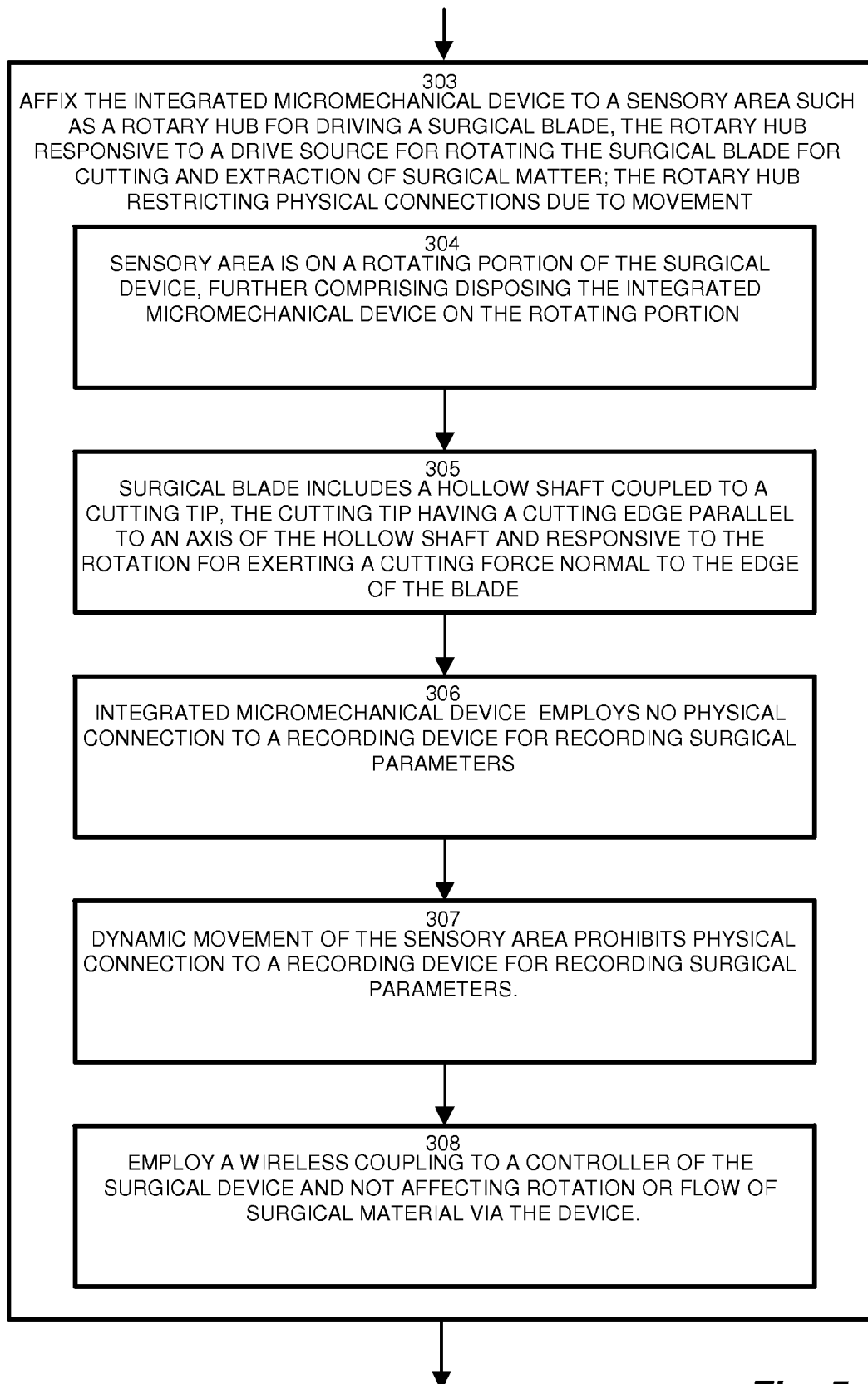
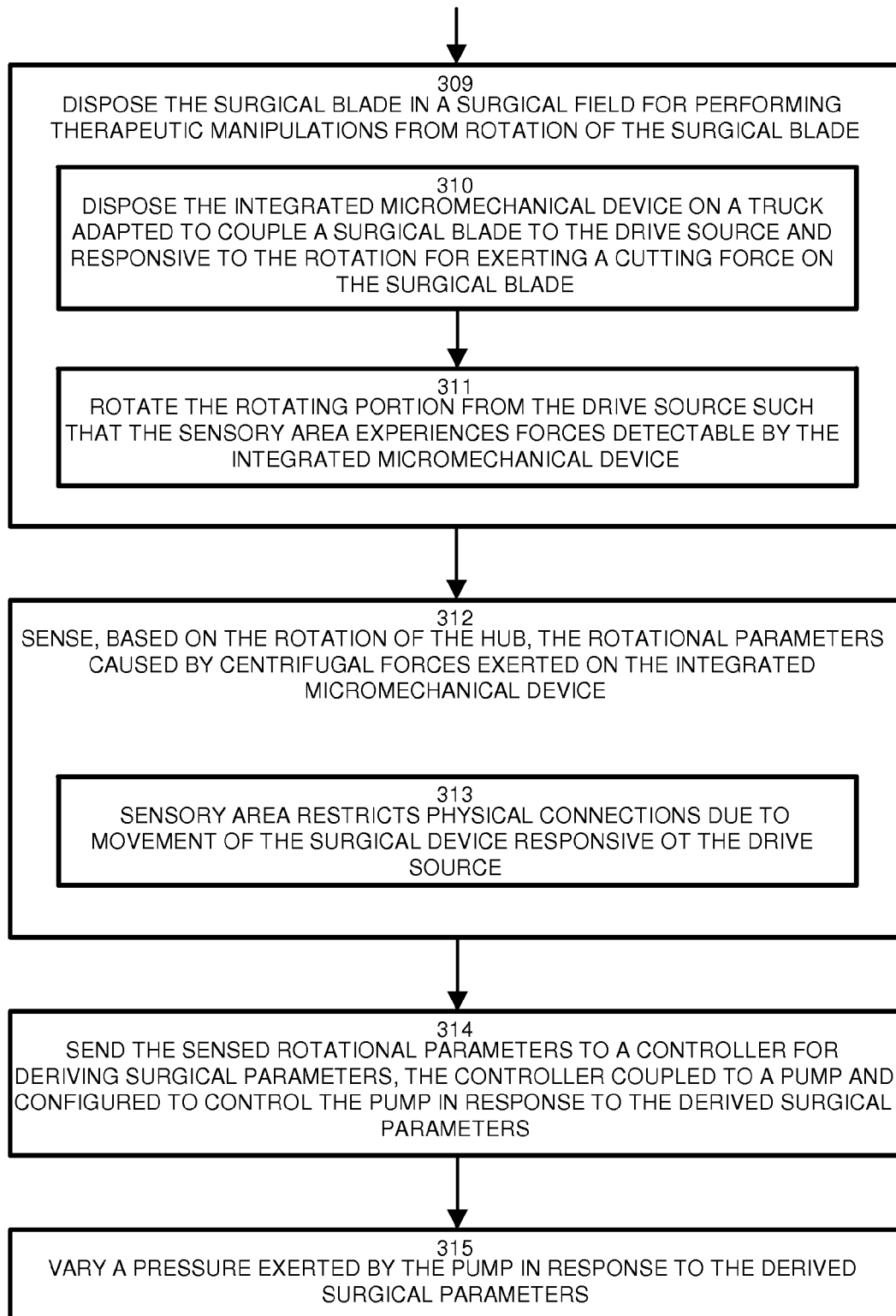


Fig. 3

**Fig. 4**

**Fig. 5**

**Fig. 6**

DYNAMIC ORTHOSCOPIC SENSING**BACKGROUND**

Design and development of electronics has steadily been following a downsizing trend ever since Gordon Moore, cofounder of Intel® corporation, suggested in 1965 that the transistor density (hence computing power) of a given chip area doubles roughly every 24 months, in a somewhat prophetic assertion that has become widely known as “Moore’s Law.” Medical devices and apparatus are no exception to the trend of electronics miniaturization. Micro-electronics are often employed as sensors for providing diagnostic feedback on routine patient status, such as for sensing pulse, oxygen saturation, body temperature, and fetal vitals during childbirth.

During surgical procedures, sensing often extends to drive mechanisms for surgical instruments, such as an orthoscopic shaver or cutter systems. Orthoscopic surgical devices (and other endoscopic devices) perform minimally invasive procedures through apertures (holes) that provide access to a surgical field, in contrast to traditional open surgery that requires an incision along the entire surgical field. Orthoscopic procedures, therefore, often occur in confined spaces inside the abdominal cavity of a patient, using elongated probes of the orthoscopic surgical instruments. These instruments often require precise manipulation to navigate the narrow clearances of the surgical field. Accordingly, orthoscopic surgical devices and instruments avoid bulky and/or unwieldy design which may interfere with precise manipulations of the surgeon.

SUMMARY

A dynamic sensing method and apparatus employs micro-electromechanical systems (MEMS) and nanoelectromechanical (NEMS) surgical sensors for gathering and reporting surgical parameters pertaining to a drive mechanism of a surgical device, such as speed, rotation, torque and other characteristics of the surgical device. Micromechanical devices, in contrast to conventional electronics, are small machines adapted for physical transitions such as movement of levers, gears, and transducers, in addition to computational execution the surgical device employs or affixes the surgical sensor on or about a surgical device for detecting electromechanical characteristics during the surgical procedure. The surgical procedure disposes the medical device in the surgical field responsive to the drive mechanism of a shaver or other endoscopic instrument inserted in a surgical field defined by the surgical procedure.

Conventional sensors for providing diagnostic feedback for orthoscopic procedures tend to crowd the surgical field and require additional tethers (wired connections) to the instruments. The reduced size of the surgical sensor allows nonintrusive placement in the surgical field, such that the sensor does not interfere with or adversely affect the drive operation of the surgical device for which it is to measure surgical parameters. The reduced size is also favorable to manufacturing costs and waste for single use and disposable instruments, which are discarded after usage on a single patient.

In configurations disclosed below, a surgical device drive employs MEMS or NEMS surgical sensors to provide performance data and statistics to the drive mechanism for use as feedback and control parameters to vary, for example, shaver speed and rotation proportional to a pump evacuating the surgical field. The surgical sensor is affixed or otherwise

disposed on a “truck” or rotating hub of the shaver. A cutting blade extends axially from the truck for transferring rotary motion to a cutting edge at an opposed end of the cutting blade. The truck rotates in response to the drive mechanism for providing a cutting and/or extraction force to the shaver, by rotating in a constant or oscillating manner to transfer cutting force to the cutting edge. The surgical sensor detects rotation, speed, and torque of the shaver, for detecting speed indicative of an incision rate, and torque which may indicate an upper limit of structural stability of the truck and blade assembly.

Configurations herein are based, in part, on the observation that conventional approaches employ RFID (Radio Frequency Identification) tags on surgical tools and equipment for tracking during a surgical procedure. While RFIDs can be fabricated to be small and passive (i.e. externally powered by the triggering signal), computation and execution power is limited. Unfortunately, therefore, conventional approaches to parameter sensing suffer from the shortcoming that response is typically limited to identification of the device or instrument on which the RFID is affixed, and information other than identity is unavailable, due to limited computational ability that may be encoded on an RFID.

Accordingly, configurations herein substantially overcome the above described shortcomings by providing an unobtrusive sensor disposed on a surgical device responsive to a drive mechanism for sensing dynamic attributes such as speed, rotation and torque and for transmitting the sensed attributes via a wireless interface to a drive source for responsive control. The wireless interface allows affixation of the surgical sensor to a rotating or moving component of the surgical device, and the micromechanical nature allows placement in a noninterfering location that does not adversely affect surgical device operation.

In further detail, the method provides dynamic surgical feedback during a surgical or therapeutic procedure by identifying a sensory area on a surgical device, such that the sensory area is adapted to receive an integrated micromechanical device and responsive to sensed electromechanical stimuli during a surgical procedure. The surgical device is coupled to a drive source for performing surgical manipulations, and the integrated micromechanical device is affixed to the sensory area for detecting surgical parameters dynamically during the surgical procedure. The integrated micromechanical device (micromechanical device) maintains wireless communication with a controller responsive to the integrated micromechanical device for dynamically receiving the detected surgical parameters from the integrated micromechanical device during the surgical procedure, and placement in a non-interfering sensory area provides that the sensed surgical parameters are unaffected by the presence of the micromechanical device due to unobtrusive placement of the integrated micromechanical device at the sensory area.

In a particular configuration, the claimed approach has particular utility in an endoscopic procedure such as a knee joint surgery, discussed herein as an example application. In a medical device environment, the method controls a surgical extraction device, such as a shaver, and including an integrated micromechanical device configured for rotational sensing, and establishes a wireless connection from the micromechanical device to a controller for sending sensed rotational parameters. An attachment mechanism affixes the integrated micromechanical device to a rotary hub for driving a surgical blade, in which the rotary hub is responsive to a drive source for rotating the surgical blade for cutting and extraction of surgical matter. As the rotary hub restricts

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physical connections due to movement (rotation), the wireless connection mitigates the need for physical tethered connections. The surgeon disposes the surgical blade in a surgical field for performing therapeutic manipulations from rotation of the surgical blade, and the micromechanical device senses, based on the rotation of the hub, the rotational parameters caused by centrifugal forces exerted on the micromechanical device. The micromechanical device sends the sensed rotational parameters to a controller for deriving surgical parameters, in which the controller is coupled to a pump and configured to control the pump in response to the derived surgical parameters, therefore providing proportional control for the pump in response to shaver activity.

Alternate configurations of the invention include a multiprogramming or multiprocessing computerized device such as a multiprocessor, controller or dedicated computing device or the like configured with software and/or circuitry (e.g., a processor as summarized above) to process any or all of the method operations disclosed herein as embodiments of the invention. Still other embodiments of the invention include software programs such as a Java Virtual Machine and/or an operating system that can operate alone or in conjunction with each other with a multiprocessing computerized device to perform the method embodiment steps and operations summarized above and disclosed in detail below. One such embodiment comprises a computer program product that has a non-transitory computer-readable storage medium including computer program logic encoded as instructions thereon that, when performed in a multiprocessing computerized device having a coupling of a memory and a processor, programs the processor to perform the operations disclosed herein as embodiments of the invention to carry out data access requests. Such arrangements of the invention are typically provided as software, code and/or other data (e.g., data structures) arranged or encoded on a computer readable medium such as an optical medium (e.g., CD-ROM), floppy or hard disk or other medium such as firmware or microcode in one or more ROM, RAM or PROM chips, field programmable gate arrays (FPGAs) or as an Application Specific Integrated Circuit (ASIC). The software or firmware or other such configurations can be installed onto the computerized device (e.g., during operating system execution or during environment installation) to cause the computerized device to perform the techniques explained herein as embodiments of the invention.

BRIEF DESCRIPTION OF THE DRAWINGS

The foregoing and other objects, features and advantages of the invention will be apparent from the following description of particular embodiments of the invention, as illustrated in the accompanying drawings in which like reference characters refer to the same parts throughout the different views. The drawings are not necessarily to scale, emphasis instead being placed upon illustrating the principles of the invention.

FIG. 1 is a context diagram of a medical device environment suitable for use with configurations disclosed herein;

FIG. 2 is a flowchart of dynamic parameter sensing as disclosed herein;

FIG. 3 is a diagram of sensor deployment in the environment of FIG. 1; and

FIGS. 4-6 are a flowchart of endoscopic sensory arrangements during a surgical procedure.

DETAILED DESCRIPTION

Depicted below is an example configuration of a medical device environment employing dynamic feedback via

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micromechanical surgical sensors. In the example shown, the surgical device is a surgical shaver responsive to a drive source for providing rotational movement for excising and removing surgical material such as bone and tissue from the surgical field. The surgical sensor is affixed to a so-called truck, or rotating hub, responsive to the drive source. A cutting edge at the end of the cutting blade rotates or oscillates to extract the surgical material, and a hollow interior of the tubular blade allows evacuation by a pump, also controlled by the drive source.

FIG. 1 is a context diagram of a medical device environment **100** suitable for use with configurations disclosed herein. Referring to FIG. 1, the medical device environment **100** employs an integrated micromechanical device (micromechanical device) **110** for placement within the surgical environment, such as in a shaver **130**, shown as **110-1** or at a surgical field **154** of the patient **132**, shown as **110-2** (**110** generally). The micromechanical device **110**, in a particular configuration, is a MEMS or NEMS device and maintains a wireless connection **112** to a drive controller **120** or other centralized controller responsive to signals **122** to (**122-1**) and from (**122-2**) a wireless antenna **124**. The micromechanical device **110** includes a receiver **115** responsive to the signals **122-2** from the antenna **124** for requesting sensing of surgical parameters, and a transmitter **113** configured to transmit the sensed surgical parameters back to the controller **120** via signals **122-1**, and may include other sensing, computation, and power components **117**. The micromechanical device **110** may be passive, such that the signals **122-2** also provide power to the device **110**, and is sufficiently small such that received signals **122-2** permit operation and transmission of sensed parameters **122-1**, and the micromechanical device **110** may have other sensory areas, processing functions or mechanical features responsive to the signal **122-2**.

Placement of the micromechanical device **110** is such that it directly senses surgical parameters such as speed, rotation and torque, and may include affixation to the interior of a surgical shaver **130**, shown as micromechanical device **110-1**, or may operate directly within the surgical site **154**. The micromechanical device **110**, once disposed, activates from a signal **122-2** from the controller **120**, and performs sensing, computation and transmission tasks for returning the sensed surgical parameters **122-1**. The shaver **130** configuration affixes the micromechanical device **110-1** to the truck or hub **180** which is then inserted into a surgical site for surgical cutting and evacuation, discussed further below with respect to FIG. 3.

FIG. 2 is a flowchart of dynamic parameter sensing as disclosed herein. In the surgical device environment **100**, the disclosed method of controlling a surgical appliance includes, at step **200**, identifying a sensory area on a surgical device **130**, such that the sensory area **131** is responsive to sensed electromechanical stimuli during a surgical procedure. The surgical device **130** couples to a drive source **120** for performing surgical manipulations such as drilling or pumping. In a rotary device such as the example shaver **130**, for example, the sensory area **131** may be on a rotating part subject to centrifugal forces from the drive source **120** during operation. Various sensing capabilities may be employed in the micromechanical device **110-1**, such as variable resistance, pressure sensing, gyroscopic and strain gauge sensing, to name several.

An attachment mechanism affixes the integrated micromechanical device **110-1** to the sensory area **131** for detecting surgical parameters dynamically during the surgical procedure, as shown at step **201**. The attachment mechanism

may be any suitable affixation, such as pins, glue, solvent welding, or may be a feature of the surgical instrument fabrication, such as a cavity or pocket formed during casting, for example.

The micromechanical device **110** maintains wireless communication with the drive controller **120** for dynamically receiving the detected surgical parameters as signals **122-1** from the integrated micromechanical device **110** during the surgical procedure, as depicted at step **202**. Location and size of the device **110** is such that the surgical parameters are unaffected by the presence of the integrated micromechanical device due to unobtrusive placement of the integrated micromechanical device at the sensory area **131**.

FIG. 3 is a diagram of sensor deployment in the environment of FIG. 1. Referring to FIGS. 1 and 3, an example arrangement of micromechanical device **110** deployment in an endoscopic knee procedure is depicted. A surgeon disposes the shaver **130** through an endoscopic aperture **150** in the knee **152** of a patient. The shaver **130** extends through skin and soft tissue into a surgical void **154** between the femur **156** and tibia **158**. The shaver **130** includes a drive connection **160**, for coupling to a drive port **162** of the controller **120** via a drive cable **182**. The drive connection **160** may receive electric, pneumatic, hydraulic, or other suitable drive medium for powering the hub **180** and attached surgical blade **162** and cutting edge **164**. The shaver **130** also includes a suction port **170** for coupling to an evacuation port **172** via a tube set **174**. The drive controller **120** applies suction (typically via a surgical pump) for evacuating surgical material from the shaver via the hollow core **176** of the surgical blade **162**. Alternatively, a separate pump may be employed distinct from the drive controller **120** powering the shaver **130**. The procedure may also include one or more cannulas **140** having a micromechanical device **110-3** affixed to the interior of a delivery tube **160** of the cannula **140** for sensing pressure, flow and temperature of saline pumped through the cannula delivery tube **160**, and for additional irrigation or evacuation (suction) of the surgical site.

FIGS. 4-6 are a flowchart of endoscopic sensory arrangements during a surgical procedure. Referring to FIGS. 1 and 3-6, a method of controlling a surgical extraction device such as a shaver **130** includes configuring an integrated micromechanical device **110-1** for rotational sensing, as depicted at step **300**. In the example arrangement, this includes configuring the micromechanical device **110-1** for sensing at least one of speed, rotation or torque of the surgical device, in which the integrated micromechanical device comprises at least one of a strain gauge, miniature gyro or a pressure sensor/transducer, as disclosed at step **301**. Various sensing and computational capabilities may be configured or fabricated on the micromechanical device **110**. In particular, rotational sensing due to centrifugal force, or detecting alternating orientations through a gravitational field, may indicate rotation. The micromechanical device **110** is also equipped for establishing a wireless connection **122-1** from the integrated micromechanical device **110-1** to a controller **120** for sending sensed rotational parameters, as depicted at step **302**.

The MEMS equipped shaver **130** affixes the integrated micromechanical device **110** to a sensory area **131** such as a rotary hub **180** for driving a surgical blade, as disclosed at step **303**, in which the rotary hub **180** is responsive to a drive source or controller **120** for rotating the surgical blade **162** for cutting and extraction of surgical matter. The wireless capability provides for gathering of surgical parameters despite the rotary hub **180** restricting physical connections

due to movement (rotation). In the shaver **130** example shown, the sensory area **131** is on a rotating portion of the surgical device (hub of shaver **130**), and affixation disposes the integrated micromechanical device **110** on the rotating portion **180**, as depicted at step **304**.

The surgical blade **162** extending from the hub **180** includes a hollow shaft or bore **176** coupled to a cutting tip **164**, such that the cutting tip **164** has a cutting edge parallel to an axis of the hollow shaft and responsive to the rotation for exerting a cutting force normal to the edge of the blade **162**, as disclosed at step **305**. The micromechanical device **110** therefore employs no physical connection to a recording device for recording the surgical parameters due to the rotation of the hub **180**, as shown at step **306**, as dynamic movement of the sensory area **131** prohibits physical connection to a recording device for recording surgical parameters, as depicted at step **307**. Rather, gathering surgical parameters is facilitated from unobtrusive placing of a wireless coupling (i.e. transmitter **113**) to a controller of the surgical device **130** that does not affecting rotation or flow of surgical material via the device **130**, as disclosed at step **308**.

In the course of a surgical or therapeutic procedure, a surgeon disposes the surgical blade **162** into the surgical field **154** for performing therapeutic manipulations from rotation of the surgical blade **162**, as shown at step **309**. This includes disposing the micromechanical device **110** on a truck **180** adapted to couple the surgical blade **162** to the drive source **120** and responsive to the rotation for exerting a cutting force on the cutting edge **164** via the surgical blade **162** via, as depicted at step **310**. The drive source **120** rotates the rotating portion **180** via a drive cable **182** from the drive controller **120** such that the sensory area **131** experiences forces detectable by the micromechanical device **110-1**, as disclosed at step **311**.

The micromechanical device **110** senses, based on the rotation of the hub **180**, the rotational parameters caused by centrifugal forces exerted on the micromechanical device **110-1**, as shown at step **312**. The sensory area **131** restricts physical connections due to movement of the surgical device **130** responsive to the drive source **120**, as depicted at step **313**, such as rotation of the hub **180** or other drive mechanism. Alternate configurations may deploy various sensing capabilities on the micromechanical device **110**. A strain gauge may be employed to detect torque by sensing surface variations on the hub **180** for sensing excessive and damaging force that could fracture the hub **180**. Centrifugal or gravitational variations may be sensed by a pressure sensitive resistor or gyroscope, for example. In the particular shaver arrangement shown, the micromechanical device **110-1** sends the sensed rotational or other sensed parameters to the controller **120** for deriving the surgical parameters, in which the controller **120** is coupled to a pump and configured to control the pump in response to the derived surgical parameters, as depicted at step **314**. In such a configuration, the drive controller **120** varies pressure exerted by the pump in response to the derived surgical parameters, as disclosed at step **315**, to provide a level of suction pressure proportional to the evacuation of surgical material resulting from the speed and cutting force of the surgical blade **162**.

Conventional approaches are shown by U.S. Publication No. 2007/0078484, to Talarico et al. (Talarico '484), which discloses a surgical grasper comprising a handle and two jaws operably connected to and actuated by the handle. A sensor is located on an inner surface of one or both of the jaws for direct measurement of an amount of pressure or force being applied with the grasper, referring to paragraph

[0006]. While Talarico '484 suggests MEMS based sensors at paragraph [0047]-[0048], the sensors are for detecting pressure or force between the jaws. In contrast to the proposed approach, there is no showing, teaching, or disclosure of rotary based parameters such as torque, speed or rotation. Further, such rotary parameters would be inapplicable to the linear forces pertaining to the closure of the jaw surfaces.

Another application, U.S. Publication No. 2008/0167672 by Giordano (Giordano '672), teaches a surgical instrument comprising at least one sensor transponder, such as endoscopic or laparoscopic surgical instruments. Giordano '672 is directed to surgical instruments where some feature of the instrument, such as a free rotating joint, prevents or otherwise inhibits the use of a wired connection to the sensor(s), as discussed at [0033]. While Giordano '672 refers to MEMS technology, the '672 publication only employs sensors in the articulated jaws of the end effector 12, as disclosed at paragraph [0057], and makes no suggestion of continued rotation as in a shaft drive. Accordingly, Giordano '672 does not show, teach or disclose MEMS sensors disposed in a rotary configuration or coupling for sensing and transmitting operational parameters related to the rotating movement, in contrast to the proposed approach.

U.S. Publication No. 2005/0131390 ('390) teaches a surgical stapler with an end effector including a staple cartridge assembly, and an anvil operatively associated with the staple cartridge, such that the staple cartridge and the anvil are movably connected to one another to bring one into juxtaposition relative to the other. Each of the staple cartridge and the anvil define tissue contacting surfaces and the MEMS device is operatively connected to the tissue contacting surface of the staple cartridge and the tissue contacting surface of the anvil. A plurality of MEMS devices are connected to the surgical instrument, and the MEMS devices are configured and adapted to measure distance between the tissue contacting surface of the staple cartridge assembly and the tissue contacting surface of the anvil, as discussed at paragraph [0014].

The disclosed MEMS devices in the '390 application are configured and adapted to measure at least one of the amount of pressure applied to tissue and the thickness of tissue clamped between the tissue contacting surface of the staple cartridge assembly and the tissue contacting surface of the anvil, discussed at [0015]. In contrast to the proposed approach, however, there does not appear to be any disclosure of sensors applied to rotary or rotational movement, nor of associated feedback of operational data or parameters relating to rotary motion.

Those skilled in the art should readily appreciate that the programs and methods for measuring surgical parameters as defined herein are deliverable to a user processing and rendering device in many forms, including but not limited to a) information permanently stored on non-writeable storage media such as ROM devices, b) information alterably stored on writeable non-transitory storage media such as floppy disks, magnetic tapes, CDs, RAM devices, and other magnetic and optical media, or c) information conveyed to a computer through communication media, as in an electronic network such as the Internet or telephone modem lines. The operations and methods may be implemented in a software executable object or as a set of encoded instructions for execution by a processor responsive to the instructions. Alternatively, the operations and methods disclosed herein may be embodied in whole or in part using hardware components, such as Application Specific Integrated Circuits (ASICs), Field Programmable Gate Arrays (FPGAs),

state machines, controllers or other hardware components or devices, or a combination of hardware, software, and firmware components.

While the system and method of measuring surgical parameters has been particularly shown and described with references to embodiments thereof, it will be understood by those skilled in the art that various changes in form and details may be made therein without departing from the scope of the invention encompassed by the appended claims.

What is claimed is:

1. A surgical appliance comprising:

- a means for excising and removing tissue responsive to rotational movement;
- a rotary hub coupled to the means for excising and removing tissue, the rotary hub configured to provide rotational movement to the means for excising and removing tissue;
- a sensory area defined on a rotating portion of the surgical appliance; and
- an integrated micromechanical device affixed at the sensory area, the integrated micromechanical device configured to sense rotational parameters during a surgical procedure.

2. The surgical appliance of claim 1 wherein the means for excising and removing tissue responsive to rotational movement further comprises:

- a tubular member that defines a hollow core;
- a cutting tip disposed at the end of the tubular member; and
- a suction port in fluid communication with the hollow core of the tubular member.

3. The surgical appliance of claim 1 wherein the sensory area is defined on a rotating portion of the rotary hub.

4. The surgical appliance of claim 1 wherein the sensory area is defined on a rotating portion of the rotary hub.

5. The surgical appliance of claim 1 wherein:

- said means for excising and removing comprises a surgical blade;
- said sensory area defined on a rotating portion of the rotary hub.

6. The surgical appliance of claim 1 wherein the means for excising and removing further comprises a hollow shaft coupled to a cutting tip, the cutting tip having a cutting edge parallel to an axis of the hollow shaft.

7. The surgical appliance of claim 1 wherein the integrated micromechanical device is devoid of a physical connection to a recording device for recording surgical parameters.

8. The surgical appliance of claim 1 wherein the integrated micromechanical device is configured to measure at least one parameter selected from the group consisting of: speed of the surgical appliance; rotation of the surgical appliance; and torque of the surgical appliance.

9. The surgical appliance of claim 1 wherein the integrated micromechanical device further comprising at least one selected from the group consisting of: of a strain gauge; miniature gyro; and a pressure sensor/transducer.

10. A surgical system comprising:

- a surgical device that comprises:
 - a means for excising and removing tissue responsive to rotational movement;
 - a rotary hub coupled to the means for excising and removing tissue, the rotary hub configured to provide rotational movement to the means for excising and removing tissue;
 - a sensory area defined on a rotating portion of the surgical device; and

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an integrated micromechanical device affixed at the sensory area, the integrated micromechanical device responsive to sensed electromechanical stimuli during a surgical procedure;

a pump fluidly coupled to the means for excising and removing tissue;

a controller operationally coupled to the rotary hub and the pump, and the controller wirelessly coupled to the integrated micromechanical device;

the integrated micromechanical device configured to send indications of the sensed electromechanical stimuli to the controller; and

the controller configured to control a pump responsive to the indications of the sensed electromechanical stimuli.

11. The surgical system of claim **10** wherein the means for excising and removing tissue responsive to rotational movement further comprises:

a tubular member that defines a hollow core;

a cutting tip disposed at the end of the tubular member; and

a suction port in fluid communication with the hollow core of the tubular member, and the suction port fluidly coupled to the pump.

12. The surgical system of claim **10** wherein the sensory area is defined on a rotating portion of the rotary hub.

13. The surgical system of claim **10** wherein:

the means for excising and removing further comprises a surgical blade;

the sensory area defined on a rotating portion of the rotary hub; and

the surgical blade coupled to the rotary hub.

14. The surgical system of claim **10** wherein the means for excising and removing further comprises a hollow shaft coupled to a cutting tip, the cutting tip having a cutting edge parallel to an axis of the hollow shaft.

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15. The surgical system of claim **10** wherein the integrated micromechanical device is devoid of a physical connection to a recording device for recording surgical parameters.

16. The surgical system of claim **10** wherein the integrated micromechanical device is configured to measure at least one parameter selected from the group consisting of: speed; rotation; and torque of the surgical device.

17. The surgical system of claim **10** wherein the integrated micromechanical device further comprises at least one selected from the group consisting of: of a strain gauge; miniature gyro; and a pressure sensor/transducer.

18. A method of controlling a surgical extraction device comprising:

disposing a surgical blade in a surgical field, the surgical blade mechanically coupled to a rotary hub, the rotary hub having an integrated micromechanical device affixed thereto, and the rotary hub operatively coupled to a controller;

performing therapeutic manipulations by rotation of the surgical blade by the rotary hub;

sensing, based on the rotation of the hub, rotational parameters caused by centrifugal forces exerted on the integrated micromechanical device; and

sending rotational parameters sensed by the integrated micromechanical device to the controller, the sending by way of a wireless connection between the integrated micromechanical device and the controller.

19. The method of claim **18**, further comprising:

controlling, by the controller, a pump in response to surgical parameters derived from the rotational parameters.

20. The method of claim **19** further comprising varying a pressure exerted by the pump in response to the derived surgical parameters.

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